

In the Abstract:

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Abstract of the Disclosure

A method and a system for programming an industrial robot to move relative to defined positions on an object. The system includes a geometrical model of the object, the real object, and an industrial robot. A plurality of measuring points are generated corresponding to different points on the surface of the real object expressed in a coordinate system associated with the robot. The system further includes a calibration module arranged to determine orientation and position of the geometrical model of the object relative to the coordinate system associated with the robot, a calculating module arranged to calculate the deviation between the measuring points and corresponding points on the geometrical model, and an adjusting module arranged to adjust the defined positions based on the calculated deviations.